

Refine Search

Search Results -

| Term | Documents |
|--|-----------|
| POSITION | 6297148 |
| POSITIONS | 2163944 |
| UNIT | 4699658 |
| UNITS | 1640738 |
| ACQUIR\$3 | 0 |
| ACQUIR | 740 |
| ACQUIRA | 3 |
| ACQUIRAD | 1 |
| ACQUIRAL | 1 |
| ACQUIRB | 2 |
| ACQUIRBD | 3 |
| (L1 AND ((ACQUIR\$3 ADJ3 POSITION) ADJ5 (DETECT\$3 ADJ UNIT))).PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD. | 1 |

There are more results than shown above. [Click here to view the entire set.](#)

Database:

US Pre-Grant Publication Full-Text Database
 US Patents Full-Text Database
 US OCR Full-Text Database
 EPO Abstracts Database
 JPO Abstracts Database
 Derwent World Patents Index
 IBM Technical Disclosure Bulletins

Search:

L8

Refine Search

Recall Text 

Clear

Interrupt

Search History

DATE: Wednesday, November 09, 2005 [Printable Copy](#) [Create Case](#)

Set
Name Query
 side by
 side

Hit
Count Set
 Name
 result set

DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD; PLUR=YES; OP=ADJ

| | | | |
|-----------|--|-----|-----------|
| <u>L8</u> | L1 and ((acquir\$3 adj3 position) adj5 (detect\$3 adj unit)) | 1 | <u>L8</u> |
| <u>L7</u> | L1 and ((calculat\$3 adj3 map\$4 adj information)) | 3 | <u>L7</u> |
| <u>L6</u> | L1 and ((wafer or semiconductor) and (plate)) | 122 | <u>L6</u> |
| <u>L5</u> | L1 and ((au or (arithmetic adj unit)) and (calculation)) | 28 | <u>L5</u> |
| <u>L4</u> | 2000124289 | 2 | <u>L4</u> |
| <u>L3</u> | 2003116071 | 2 | <u>L3</u> |
| <u>L2</u> | L1 and ((incident adj direction) and (opposite adj direction)) | 2 | <u>L2</u> |
| <u>L1</u> | (map\$4 adj3 (apparatus or system or device)) and (reflect\$3 adj3 light) and (light adj3 project\$3) | 286 | <u>L1</u> |

END OF SEARCH HISTORY

[First Hit](#)[Previous Doc](#)[Next Doc](#)[Go to Doc#](#)

Generate Collection

Print

L4: Entry 1 of 2

File: JPAB

Apr 28, 2000

PUB-NO: JP02000124289A

DOCUMENT-IDENTIFIER: JP 2000124289 A

TITLE: HAND OF THIN SUBSTRATE TRANSFER ROBOT

PUBN-DATE: April 28, 2000

INVENTOR-INFORMATION:

NAME

COUNTRY

KIMATA, KAZUO

INUKAI, YASUHIRO

ASSIGNEE-INFORMATION:

NAME

COUNTRY

MECS CORP

APPL-NO: JP10296754

APPL-DATE: October 19, 1998

INT-CL (IPC): H01 L 21/68; B25 J 15/08

ABSTRACT:

PROBLEM TO BE SOLVED: To reduce an installation space, to decrease the number of sensors, and to shorten the line process unit time, etc., by providing a tip end part of a thin substrate transfer robot hand with an optical mapping/seating confirmation shared sensor, which acts both as an optical mapping sensor and as optical seating confirmation sensor.

SOLUTION: Related to a hand 1, a tip end part of an expansion arm is connected to a base part 2, and a pair of, left and right, holding plates 4A and 4B of drop-in-type which hold a discoidal substrate 3 are held at the base part 2. A pair of, left and right, sensor holding parts 9A and 9B are provided at the tip end part of each of holding plate parts 4A and 4B, and the sensor holding parts 9A and 9B hold an optical mapping/seating confirmation shared sensor 10 which acts both as an optical mapping sensor for detecting the presence of the discoidal thin substrate 3 and as an optical seating confirmation sensor for confirming that the discoidal thin substrate 3 is placed on the hand 1.

COPYRIGHT: (C)2000,JPO

[Previous Doc](#)[Next Doc](#)[Go to Doc#](#)